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**Becker**

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(54) **SYSTEM AND DEVICE FOR WELDING TRAINING**

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(57) **ABSTRACT**

A system and device for welding training. In one example,  
a welding training system includes a position detecting  
system configured to detect a distance between the position  
detecting system and objects within a field of view of the  
position detecting system, and to produce a map correspond-  
ing to the objects. The welding training system also includes  
a markers configured to be coupled to a device of the  
welding training system. Furthermore, the markers are con-  
figured to be detected by the position detecting system.

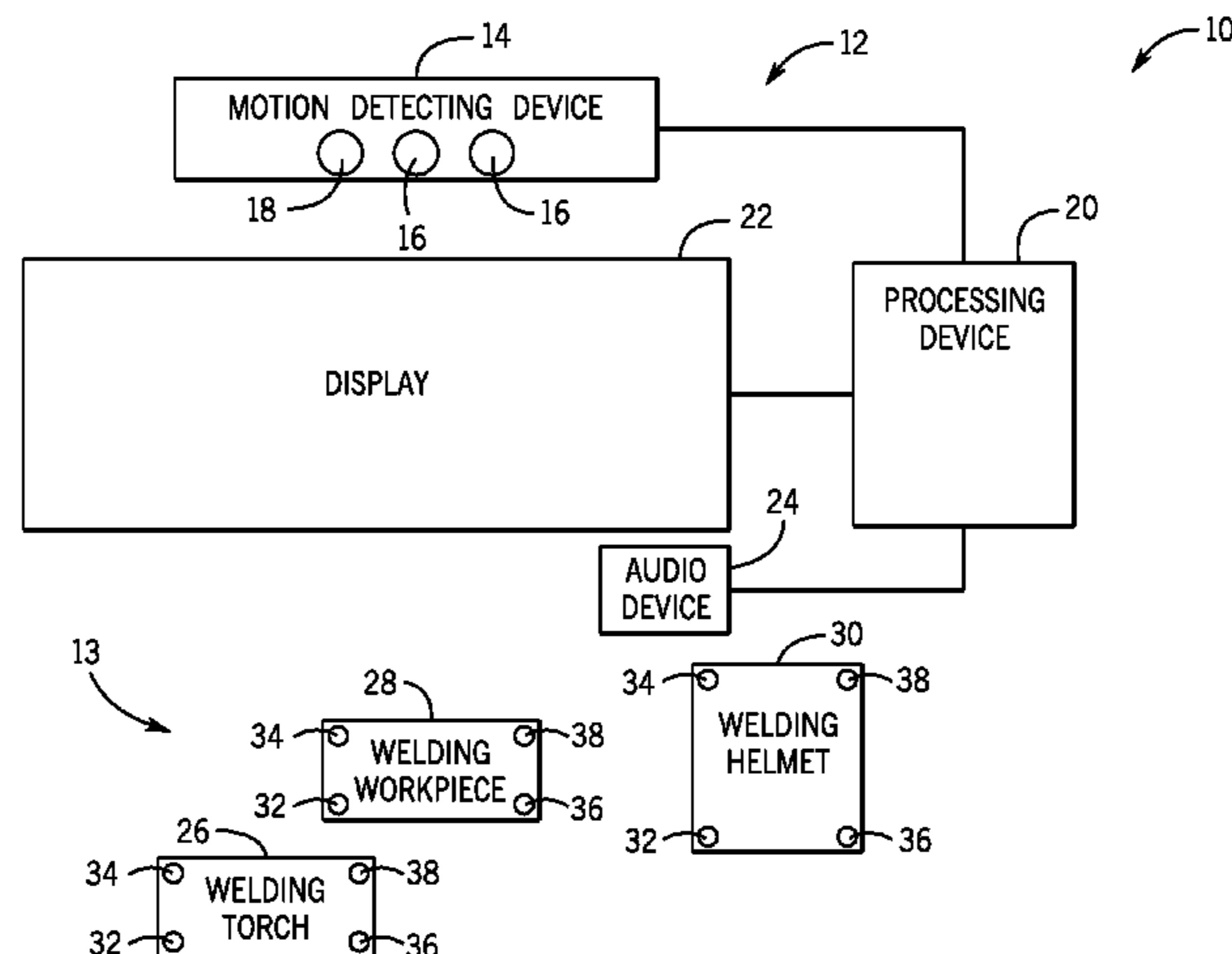
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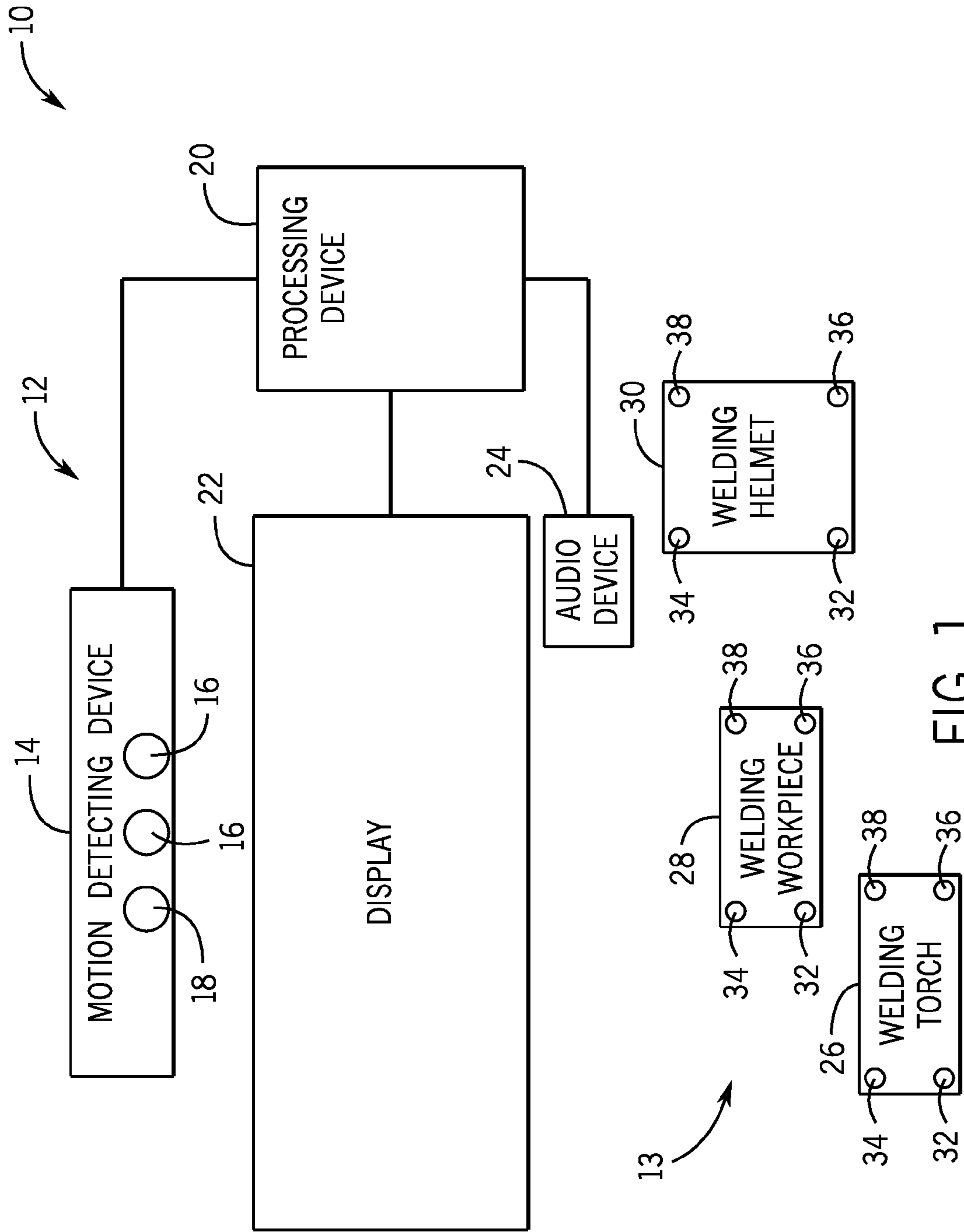
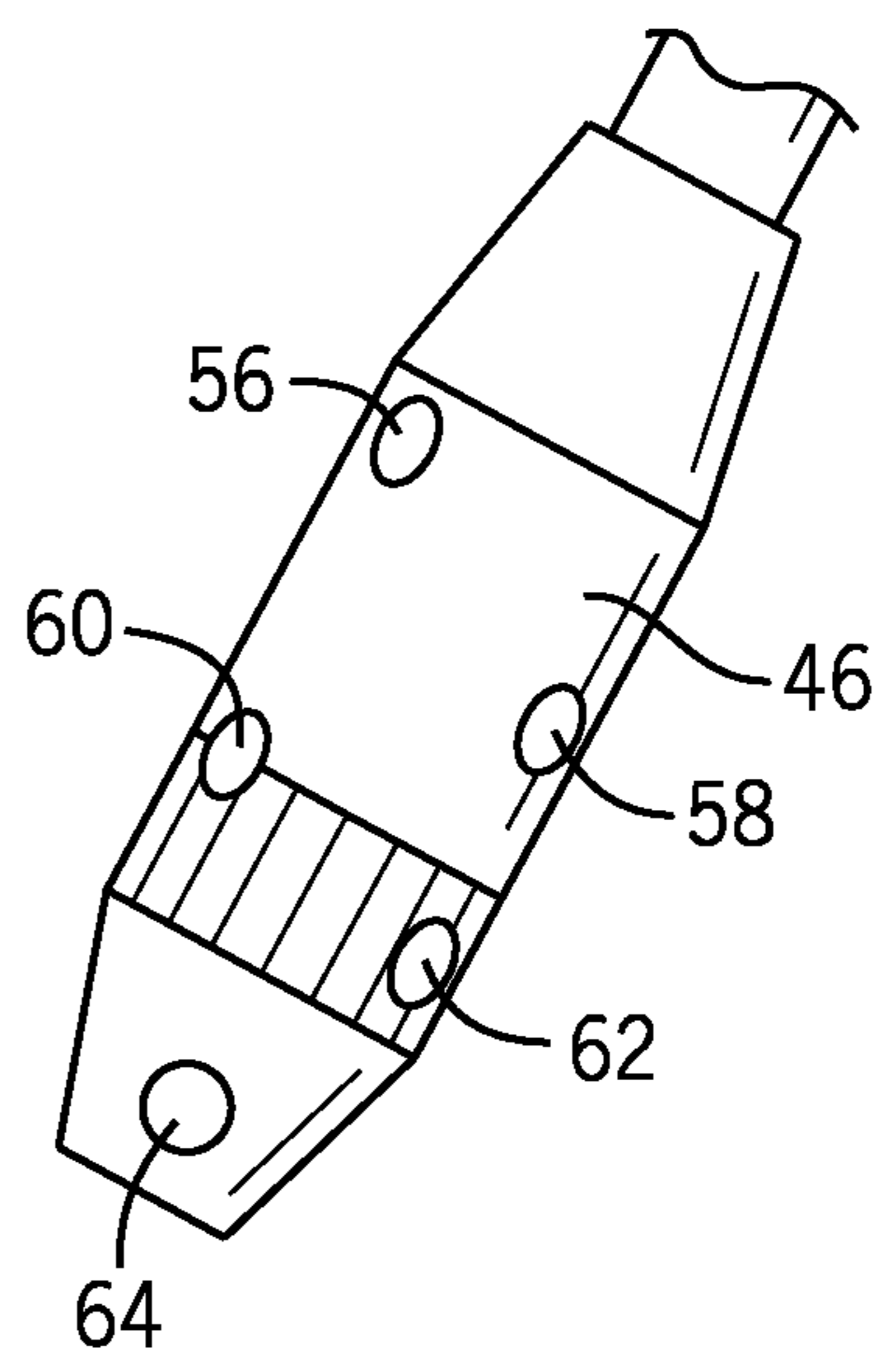
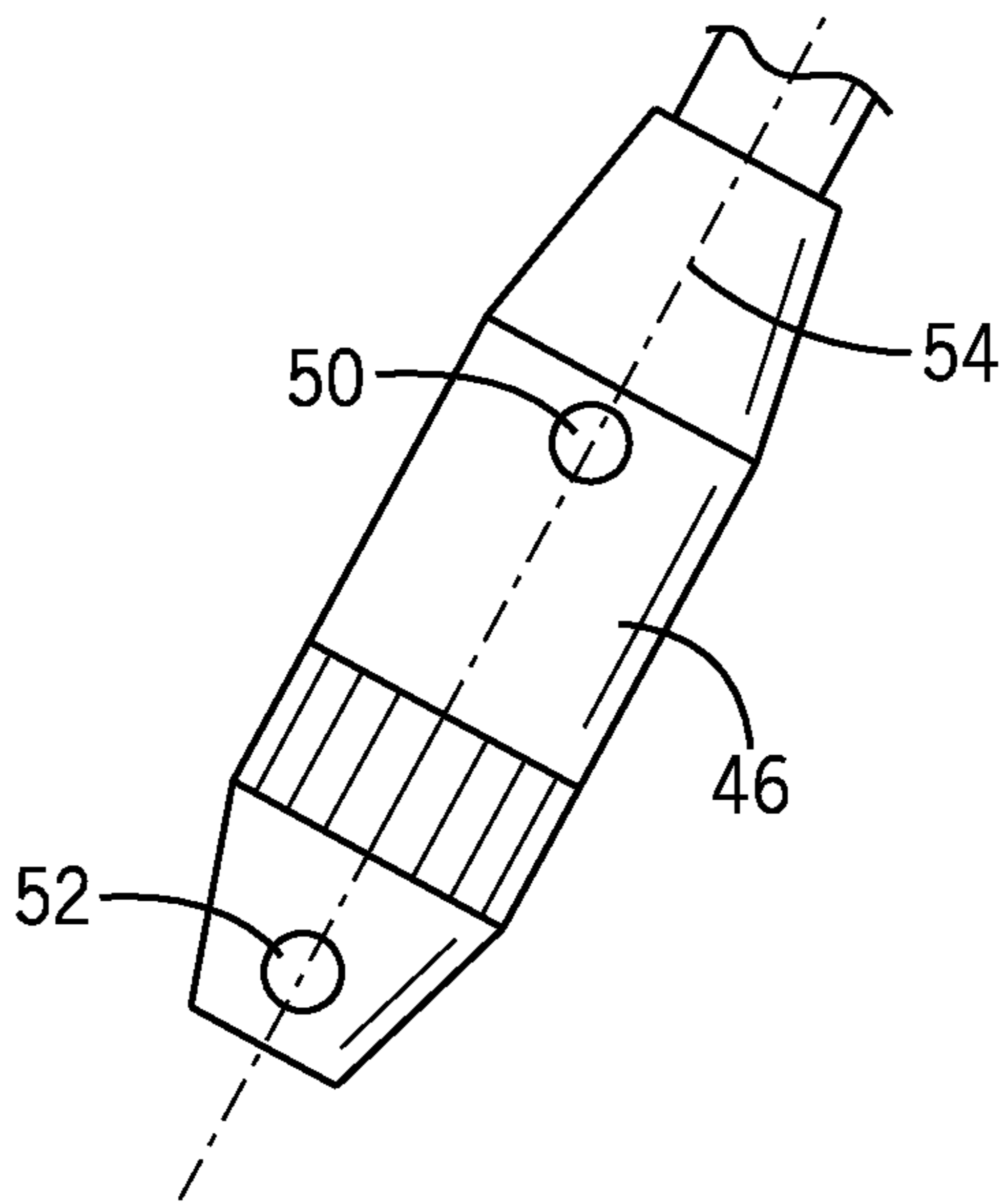
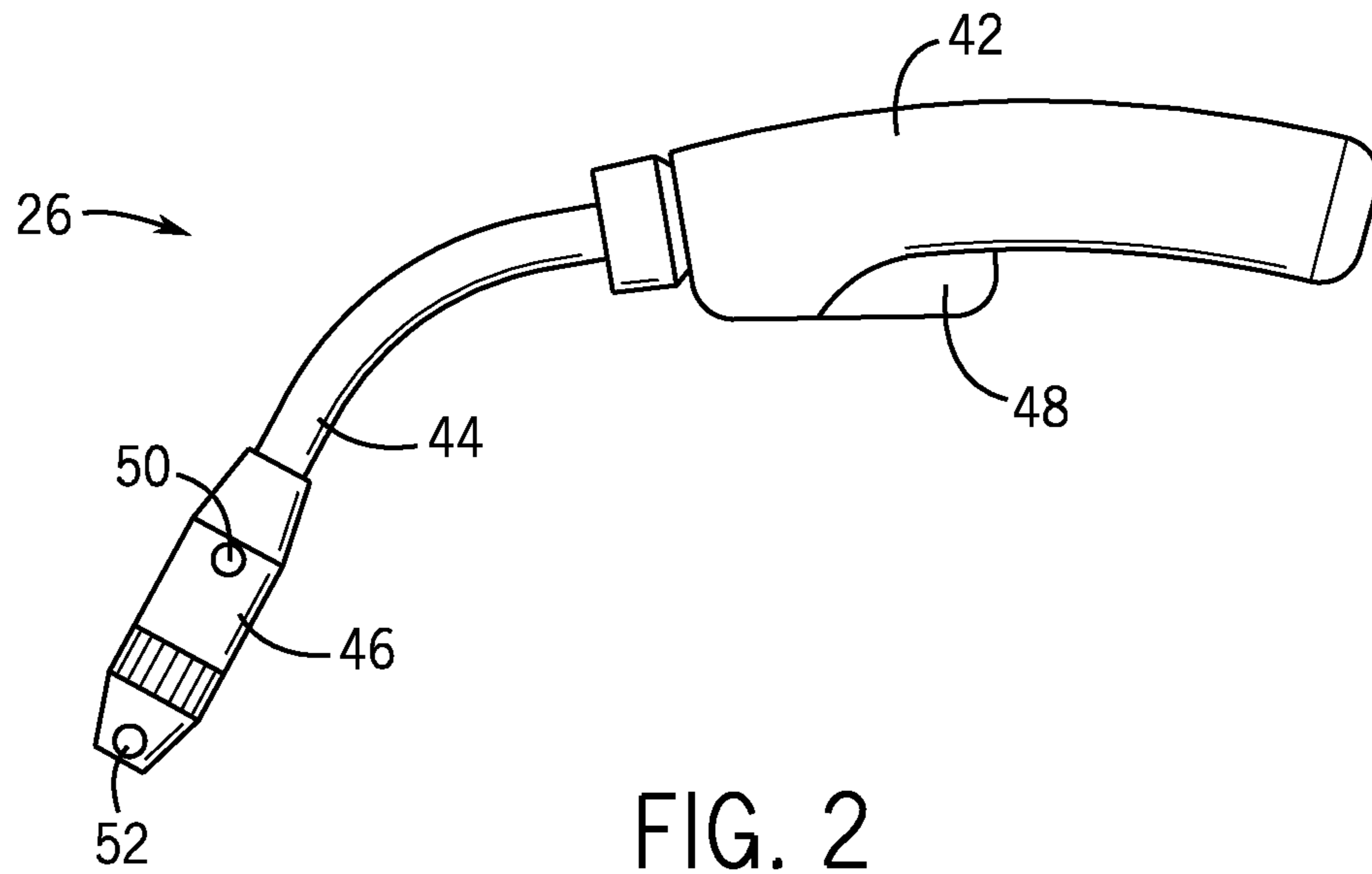


FIG. 1





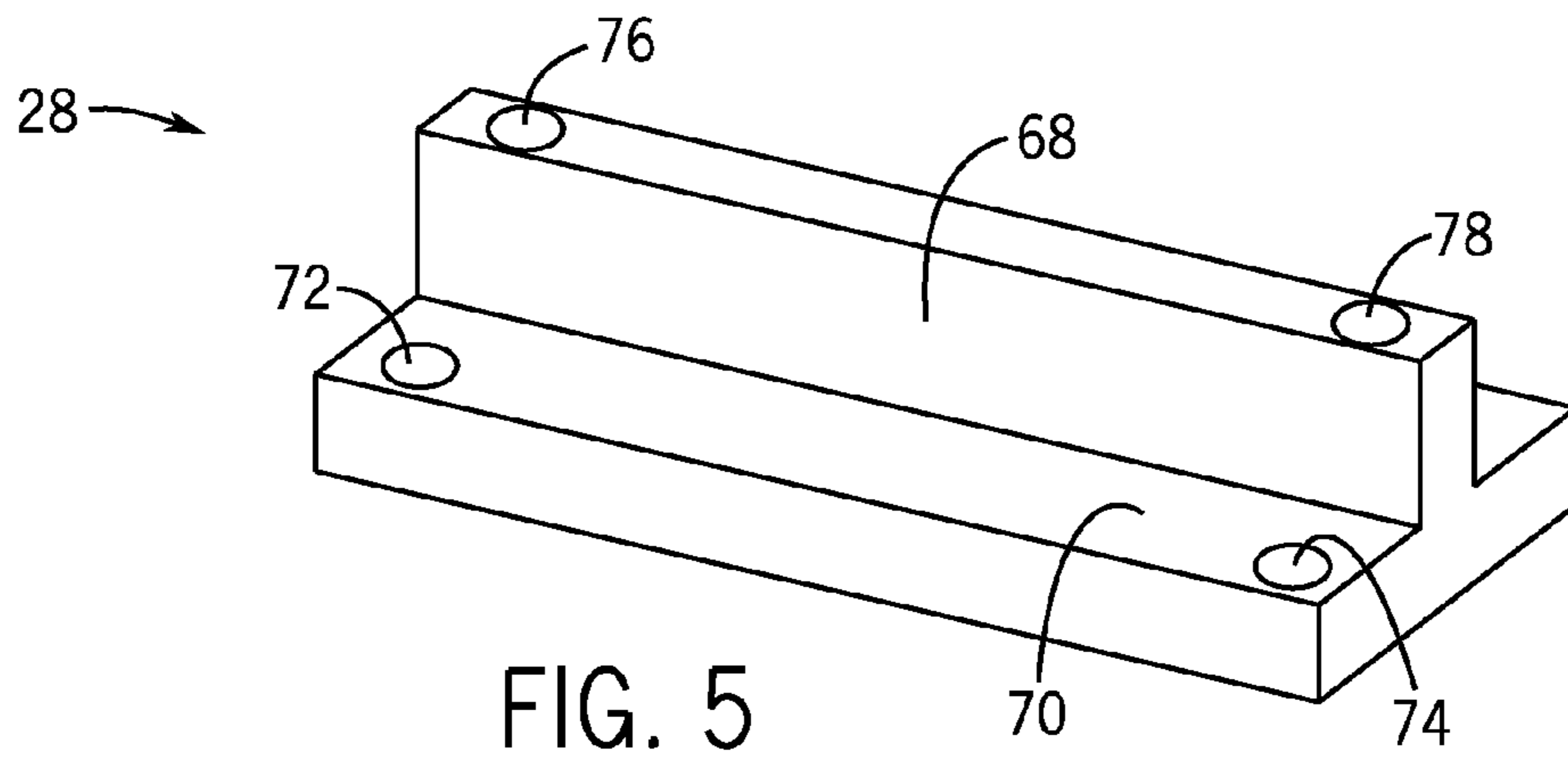


FIG. 5

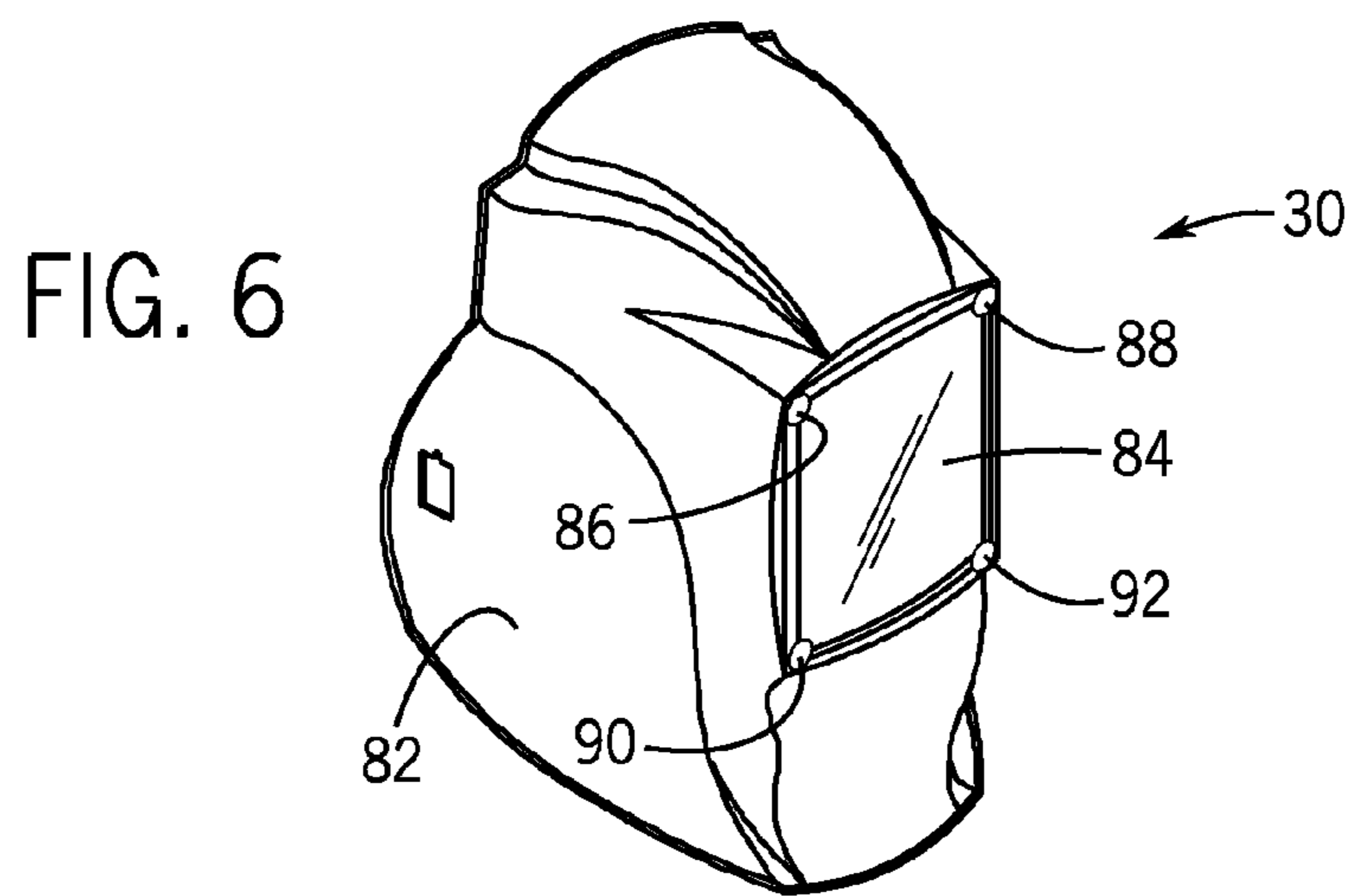


FIG. 6

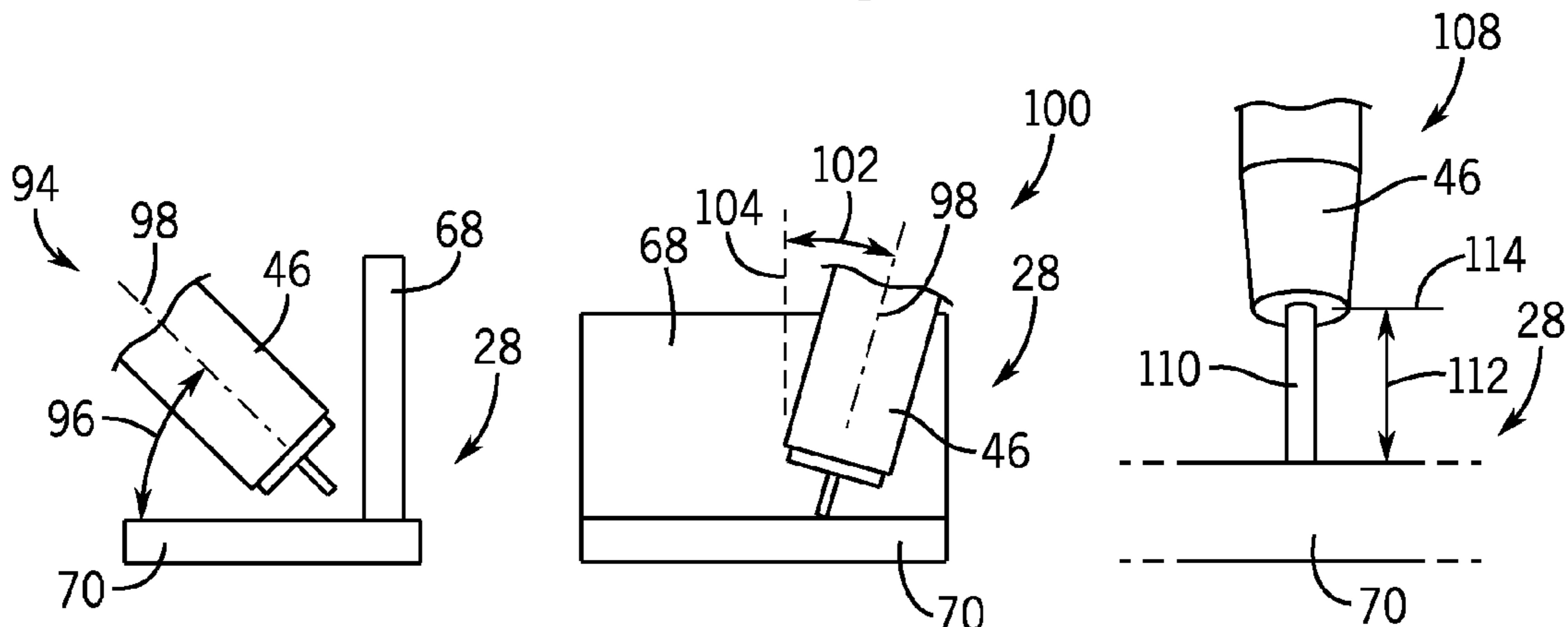


FIG. 7

FIG. 8

FIG. 9

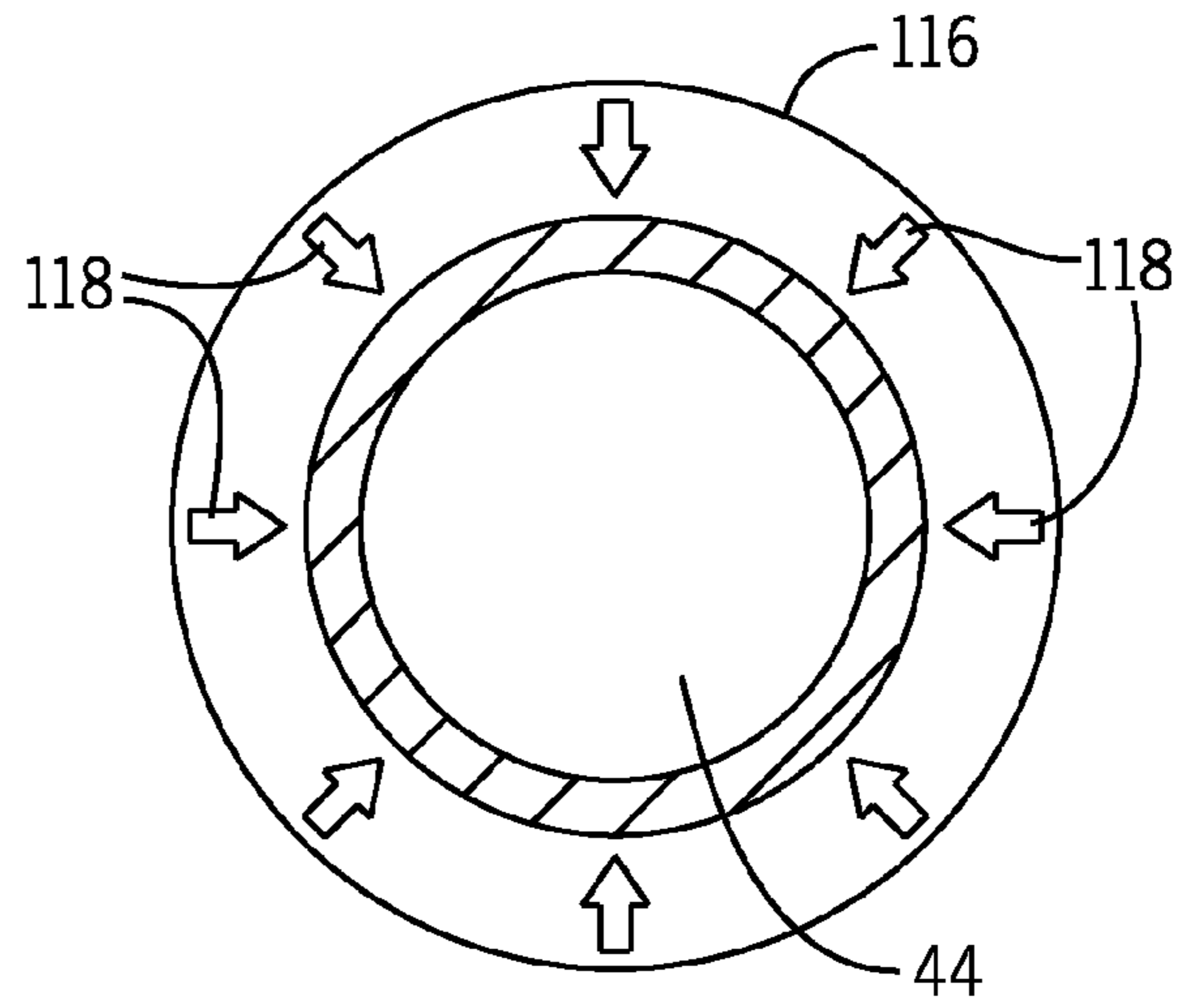


FIG. 10A

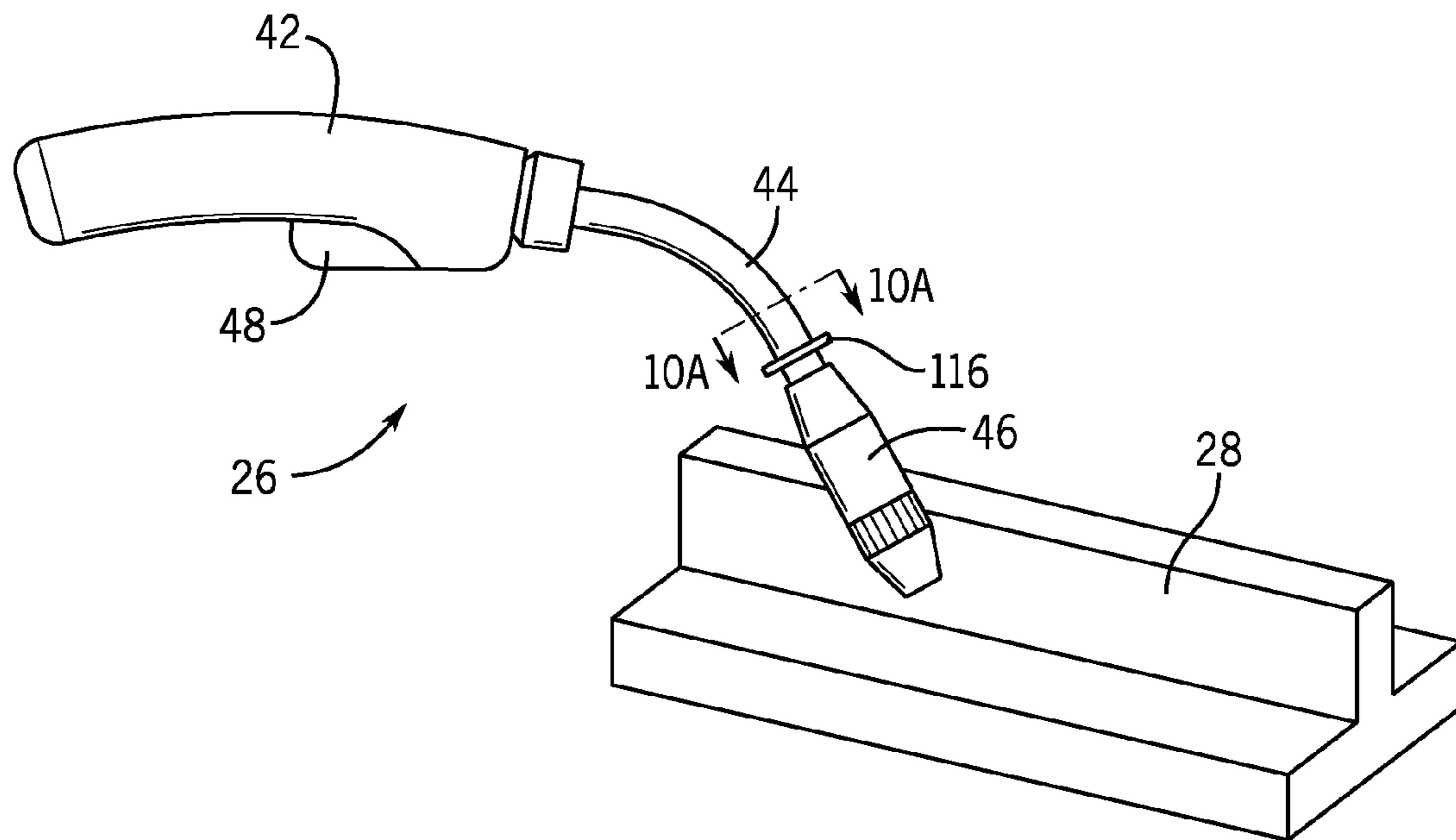
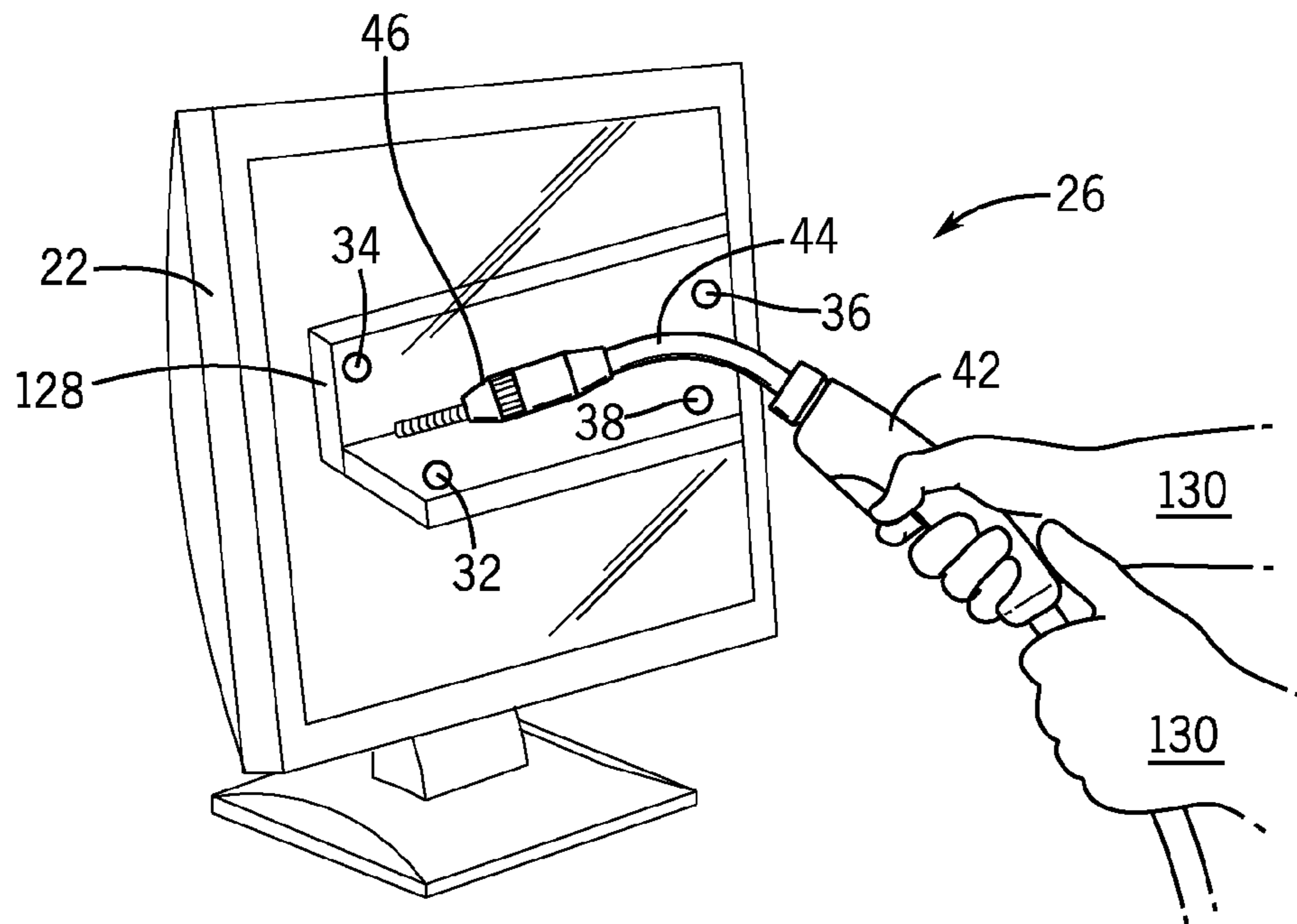
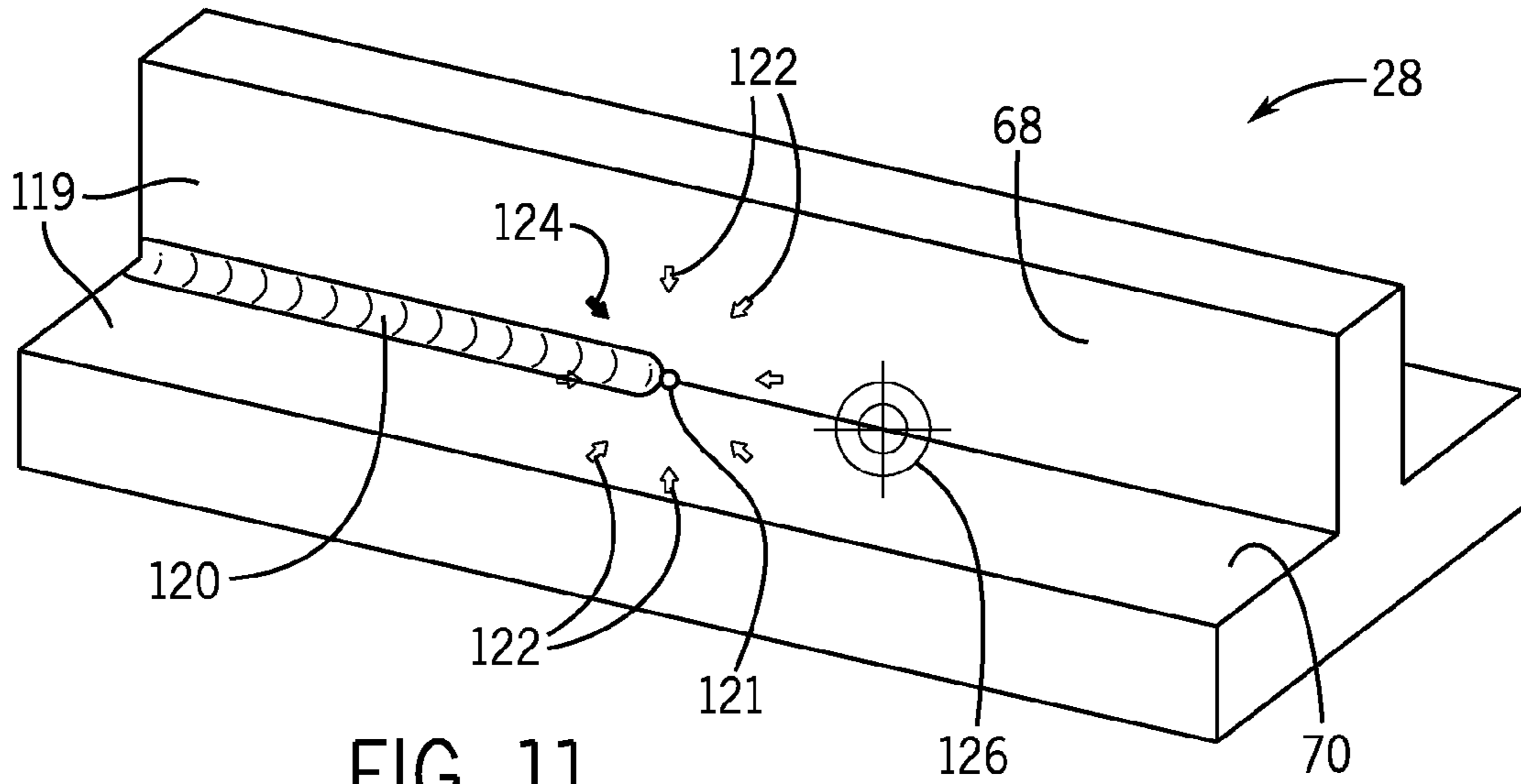


FIG. 10



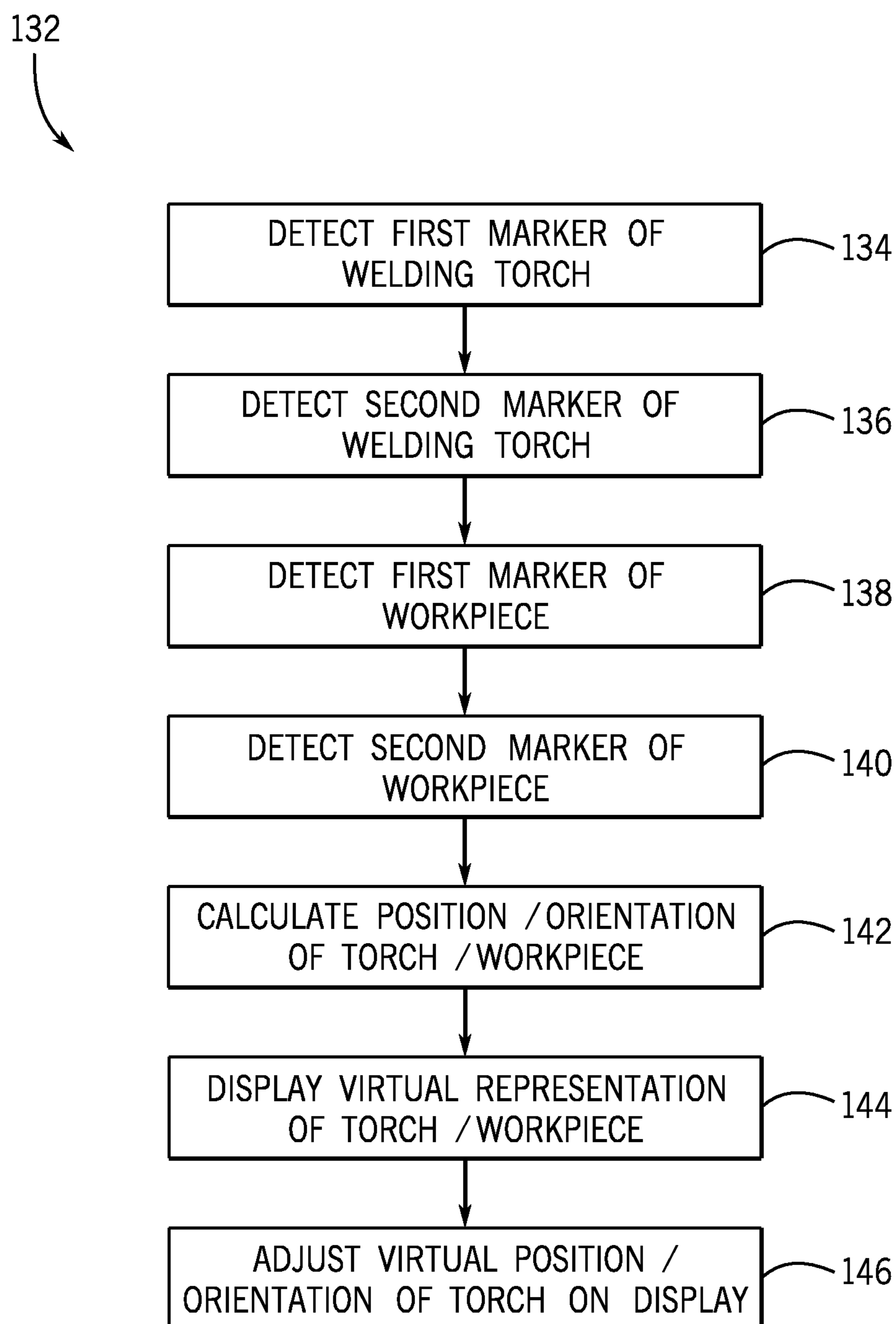


FIG. 13

## SYSTEM AND DEVICE FOR WELDING TRAINING

### CROSS REFERENCE TO RELATED APPLICATIONS

This application is a Non provisional U.S. Patent Application of U.S. Provisional Application No. 61/724,322, entitled "System and Device for Welding Training", filed Nov. 9, 2012, which is hereby incorporated by reference in its entirety.

### BACKGROUND

The invention relates generally to welding and, more particularly, to a system and device for welding training.

Welding is a process that has increasingly become utilized in various industries and applications. Such processes may be automated in certain contexts, although a large number of applications continue to exist for manual welding operations. In both cases, such welding operations rely on a variety of types of equipment to ensure the supply of welding consumables (e.g., wire feed, shielding gas, etc.) is provided to the weld in appropriate amounts at the desired time.

To perform manual welding operations, welding operators may be trained using a welding training system. The welding training system may be designed to train welding operators the proper techniques for performing various welding operations. Certain welding training systems may use virtual reality, augmented reality, or other training methods. As may be appreciated, these training systems may be expensive to acquire. Accordingly, welding training institutions may acquire a limited number of such training systems. Therefore, welding operators being trained by the welding training institutions may have a limited amount of time for hands-on training using the training systems.

### BRIEF DESCRIPTION

In one embodiment, a welding training system includes a position detecting system configured to detect a distance between the position detecting system and objects within a field of view of the position detecting system, and to produce a map corresponding to the objects. The welding training system also includes markers configured to be coupled to a device of the welding training system. Furthermore, the markers are configured to be detected by the position detecting system.

In another embodiment, a method for determining a position of a welding torch, an orientation of the welding torch, or some combination thereof, includes detecting a first marker of the welding torch using a position detecting system. The position detecting system is configured to detect a distance between the position detecting system and objects within a field of view of the position detecting system, and to produce a map corresponding to the objects. The method also includes detecting a second marker of the welding torch using the position detecting system and calculating the position of the welding torch, the orientation of the welding torch, or some combination thereof, using the detected first and second markers.

In another embodiment, a method for determining a position, an orientation, or some combination thereof, of a welding torch and a welding workpiece includes detecting a first marker of the welding torch using a position detecting system. The position detecting system is configured to detect

a distance between the position detecting system and objects within a field of view of the position detecting system, and to produce a map corresponding to the objects. The method also includes detecting a second marker of the welding torch using the position detecting system. The method includes detecting a first marker of the welding workpiece using the position detecting system and detecting a second marker of the welding workpiece using the position detecting system. The method also includes calculating the position, the orientation, or some combination thereof, of the welding torch and the welding workpiece using the first and second markers of the welding torch and the first and second markers of the welding workpiece.

### DRAWINGS

These and other features, aspects, and advantages of the present invention will become better understood when the following detailed description is read with reference to the accompanying drawings in which like characters represent like parts throughout the drawings, wherein:

FIG. 1 is a block diagram of an embodiment of a welding training system in accordance with aspects of the present disclosure;

FIG. 2 is a side view of an embodiment of a welding torch configured to be used in the welding training system of FIG. 1 in accordance with aspects of the present disclosure;

FIG. 3 is a side view of an embodiment of a nozzle of the welding torch of FIG. 2 with an orientation axis determined in accordance with aspects of the present disclosure;

FIG. 4 is a side view of an embodiment of a nozzle of the welding torch of FIG. 2 having markers positioned around the nozzle in accordance with aspects of the present disclosure;

FIG. 5 is a perspective view of an embodiment of a workpiece configured to be used in the welding training system of FIG. 1 in accordance with aspects of the present disclosure;

FIG. 6 is a perspective view of an embodiment of a welding helmet configured to be used in the welding training system of FIG. 1 in accordance with aspects of the present disclosure;

FIG. 7 is an illustration of a work angle of a welding operation in accordance with aspects of the present disclosure;

FIG. 8 is an illustration of a travel angle of a welding operation in accordance with aspects of the present disclosure;

FIG. 9 is an illustration of a contact tip-to-work distance of a welding operation in accordance with aspects of the present disclosure;

FIG. 10 is a perspective view of a welding torch having a welding guidance indicator in accordance with aspects of the present disclosure;

FIG. 10A is a top view of the welding guidance indicator of FIG. 10 in accordance with aspects of the present disclosure;

FIG. 11 is a perspective view of an embodiment of a workpiece having a display to provide guidance to a welding operator in accordance with aspects of the present disclosure;

FIG. 12 is a perspective view of an embodiment of a virtual workpiece in accordance with aspects of the present disclosure; and

FIG. 13 is an embodiment of a method for determining a position and an orientation of a welding torch and a workpiece in accordance with aspects of the present disclosure.

#### DETAILED DESCRIPTION

FIG. 1 is a block diagram of an embodiment of a welding training system 10. The welding training system 10 includes a detection system 12 and a welding system 13. As illustrated, the detection system 12 includes a motion detecting device 14 (e.g., a three-dimensional motion or position detecting device) that is used to detect position, orientation, and/or motion of objects in the vicinity of the welding system 13. The motion detecting device 14 may be configured to detect a distance between the motion detecting device 14 and all objects within a field of view of the motion detecting device 14. For example, the motion detecting device 14 may create a three-dimensional (3D) point cloud that maps a depth to each pixel of data received by a color camera of the motion detecting device 14. Furthermore, a 3D coordinate (e.g., x, y, z) may be assigned to each pixel. As may be appreciated, the motion detecting device 14 may use any suitable devices to detect the positioning and motion of the objects in the vicinity of the welding system 13. For example, in certain embodiments, the motion detecting device 14 includes built-in cameras 16 and an infrared emitter 18 that are used to determine a position and/or an orientation of devices in the welding system 13 (e.g., relative to the motion detecting device 14). In certain embodiments, the built-in cameras 16 include an RGB camera and an infrared camera. As may be appreciated, an RGB camera may be configured to detect three basic color components (e.g., red, green, blue) such that the detected three basic color components may be used to form an image. Furthermore, an infrared camera may be configured to detect infrared radiation such that the detected infrared radiation may be used to form an image. It should be noted that the motion detecting device 14 may be a commercially off-the-shelf (COTS) product available for consumer purchase. For example, the motion detecting device 14 may be a Kinect™ by Microsoft Corporation of Redmond, Wash., or a Leap device by Leap Motion of San Francisco, Calif. In addition, the motion detecting device 14 may be a computer accessory, or may be part of a video game system. Although only one motion detecting device 14 is illustrated in FIG. 1, in certain embodiments, multiple motion detecting devices 14 may be used to improve detection capabilities.

A processing device 20 (e.g., central processing unit) of the detection system 12 may be coupled to the motion detecting device 14 and may be configured to process data from the motion detecting device 14. For example, the processing device 20 may be configured to receive data from the cameras 16 and determine a position and/or an orientation of one or more detected objects based on the data. The processing device 20 may be coupled to a display 22 (e.g., tablet, touchscreen, monitor, etc.), on which images corresponding to the detected objects may be displayed. Furthermore, the processing device 20 may be coupled to an audio device 24 (e.g., speaker, microphone, etc) for providing an audio output and/or receiving an audio input.

The welding system 13 includes one or more welding devices 26, 28, and 30 that are configured to be detected by the motion detecting device 14 of the detection system 12. As may be appreciated, each of the welding devices 26, 28, and 30 may be any suitable welding device. For example, the welding devices 26, 28, and 30 may include a welding torch 26, a welding workpiece 28, a welding helmet 30, and so

forth. As illustrated, each of the welding devices 26, 28, and 30 includes markers 32, 34, 36, and 38 that are configured to be detected by the motion detecting device 14. Although the markers 32, 34, 36, and 38 are illustrated in FIG. 1 as being generally circular, the markers 32, 34, 36, and 38 may be any suitable shape (e.g., square, rectangle, star, parallelogram, trapezoid, hexagon, etc.). Furthermore, the markers 32, 34, 36, and 38 may be any suitable size and any suitable color. As may be appreciated, the shape, the size, and/or the color of each marker 32, 34, 36, and 38 may be different. Accordingly, the markers 32, 34, 36, and 38 may be configured in any suitable manner to allow the motion detecting device 14 to distinguish between the markers 32, 34, 36, and 38 in order to determine the position and/or the orientation of the welding devices 26, 28, and 30. For example, an RGB camera of the motion detecting device 14 may be used to detect markers 32, 34, 36, and 38 where each marker has a different color. The markers 32, 34, 36, and 38 may include light-emitting diodes (LEDs) (or some other device configured to be illuminated), stickers, indentions, protrusions, molded components, printed components, covers, lenses, and so forth. For example, in certain embodiments, one or more of the markers 32, 34, 36, and 38 may include a cover or lens disposed over an LED. Moreover, the covers or lenses may have different shapes, sizes, and/or colors, while LEDs disposed under the covers or lenses may not have different shapes, sizes, and/or colors. In some embodiments, the welding devices 26, 28, and 30 may be manufactured with the markers 32, 34, 36, and 38. Moreover, in other embodiments, the markers 32, 34, 36, and 38 may be coupled to the welding devices 26, 28, and 30 at any time after the welding devices are manufactured. For example, the markers 32, 34, 36, and 38 may be sold separately from the welding devices 26, 28, and 30. Accordingly, the markers 32, 34, 36, and 38 may be attached to the welding devices 26, 28, and 30 by an operator. In certain embodiments, the welding devices 26, 28, and 30 may be configured so that they do not provide an electrical signal to the motion detecting device 14 (e.g., they may be configured as passive devices such that the motion, position, and/or orientation of the welding devices 26, 28, and 30 are detected solely by the motion detecting device 14 without the welding devices 26, 28, and 30 transmitting any signals to the motion detecting device 14). However, in such embodiments, the welding devices 26, 28, and 30 may still provide data to the detection system 12 that is not related to position and/or orientation (e.g., usage time, user identification, welding training initialization, welding training completion, and so forth). For example, the trigger of the welding torch 26 may be connected to the processing device 20 to indicate start and/or stop (e.g., wired, such as via a universal serial bus (USB) connection, and/or wireless).

As may be appreciated, a welding training system 10 that uses COTS products may be considerably less expensive than a welding training system 10 that does not use COTS products. Accordingly, the welding training system 10 described herein may provide a cost savings to an establishment that trains welding operators. Furthermore, due to the low cost of the welding training systems 10 described herein, an establishment that provides welding training may be able to provide multiple welding training systems 10 to allow welding operators being trained to have a greater amount of time to use the welding training systems 10.

FIG. 2 is a side view of an embodiment of a welding torch 26 configured to be used in the welding training system 10 of FIG. 1. As may be appreciated, the welding torch 26 may be an actual welding torch used to perform real welding

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operations, or a training welding torch. Accordingly, the welding torch 26 may be detected during an actual welding operation and/or a simulated welding operation. In the present embodiment, the welding torch 26 includes a handle 42, a neck 44, and a nozzle 46. Furthermore, the handle 42 includes a trigger 48 for initiating a welding operation (e.g., either a real world welding operation or a simulated welding operation). As illustrated in FIG. 2, the handle 42 is coupled to the nozzle 46 via the neck 44. As may be appreciated, the neck 44 and the nozzle 46 may be considered “non-handle portions” of the welding torch 26. The nozzle 46 includes markers 50 and 52 that are configured to be detected by the detection system 12. In other embodiments, any suitable location on the welding torch 26 may include markers 50 and 52. As may be appreciated, the markers 50 and 52 may be any suitable size, shape, and/or color for being detected by the detection system 12. Accordingly, the detection system 12 may determine a position (e.g., x-axis, y-axis, and z-axis) of each marker 50 and 52 with respect to the motion detecting device 14 of the detection system 12.

FIG. 3 is a side view of an embodiment of the nozzle 46 of the welding torch 26 of FIG. 2 with an orientation axis 54 (e.g., a longitudinal axis of the nozzle 46). The orientation axis 54 may be determined by the detection system 12 using the markers 50 and 52. For example, the detection system 12 may detect a position of each of the markers 50 and 52 (e.g., and therefore the position of the welding torch 26) with respect to the motion detecting device 14 of the detection system 12. Furthermore, the detection system 12 may determine the orientation (e.g., pitch, roll, and yaw) of the welding torch 26 by virtually connecting the markers 50 and 52 to form the orientation axis 54.

FIG. 4 is a side view of an embodiment of the nozzle 46 of the welding torch 26 of FIG. 2 having markers 56, 58, 60, 62, and 64 positioned around the exterior of the nozzle 46. As may be appreciated, the markers 56, 58, 60, 62, and 64 may be any suitable size, shape, and/or color for being detected by the detection system 12. The markers 56, 58, 60, 62, and 64 are positioned around the nozzle 46 of the welding torch 26 so that when the welding torch 26 is moved to various positions, the nozzle 46 will still be in view of the detection system 12. Accordingly, the position and/or the orientation of the welding torch 26 may be determined as the welding torch 26 is rotated around.

The position and/or the orientation of the welding torch 26 may be determined relative to a position and/or an orientation of a workpiece. Accordingly, in some embodiments, the workpiece may be positioned in a fixed position relative to the motion detecting device 14 of the detection system 12. For example, the motion detecting device 14 and the workpiece may be positioned using a mechanical fixture to ensure that the motion detecting device 14 is at a predetermined position and/or orientation relative to the workpiece. In other embodiments, a predefined calibration procedure may be used to determine the position of the workpiece relative to the motion detecting device 14. For example, the welding torch 26 may be touched to the workpiece at different locations to allow the detection system 12 to determine the position and/or the orientation of the workpiece based on the predefined calibration procedure. Furthermore, in certain embodiments, the detection system 12 may be configured to detect the position and/or the orientation of the workpiece using markers.

Accordingly, FIG. 5 is a perspective view of an embodiment of a workpiece 28 configured to be used in the welding training system 10 of FIG. 1. In the illustrated embodiment, the workpiece 28 includes a vertical portion 68 and a

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horizontal portion 70 to be welded together (e.g., either in a real world or a virtual welding operation). As illustrated, a first set of markers 72 and 74 are positioned on the horizontal portion 70, while a second set of markers 76 and 78 are positioned on the vertical portion 68. Again, the markers 72, 74, 76, and 78 may be any suitable size, shape, and/or color for being detected by the detection system 12. Accordingly, the detection system 12 may determine a position (e.g., x-axis, y-axis, and z-axis) of each marker 72, 74, 76, and 78 of the workpiece 28. Furthermore, the detection system 12 may determine both a position and an orientation of the workpiece 28. With the position and orientation of the workpiece 28, the detection system 12 may determine the position and/or the orientation of the welding torch 26 (e.g., as described above with respect to FIGS. 2-4) relative to the workpiece 28. Although the workpiece 28 is configured for performing a tee joint, the workpiece 28 may be configured to perform a butt joint, a lap joint, or any other suitable configuration. Furthermore, the workpiece 28 may be configured for welding in any suitable orientation (e.g., flat, horizontal, vertical, overhead, etc.) and/or using any suitable welding technique (e.g., weaving, stitching, etc.).

FIG. 6 is a perspective view of an embodiment of a welding helmet 30 configured to be used in the welding training system 10 of FIG. 1. The welding helmet 30 includes a helmet shell 82 and a lens assembly 84. When worn by a welding operator, the helmet shell 82 covers the head of the operator. As may be appreciated, the welding operator views a welding operation through the lens assembly 84. As illustrated, the welding helmet 30 includes markers 86, 88, 90, and 92 of the welding helmet 30. Again, like other markers previously described, the markers 86, 88, 90, and 92 may be any suitable size, shape, and/or color for being detected by the detection system 12. Accordingly, the detection system 12 may determine a position (e.g., x-axis, y-axis, and z-axis) of each marker 86, 88, 90, and 92 of the welding helmet 30. Furthermore, the detection system 12 may determine both a position and an orientation of the welding helmet 30. With the position and orientation of the welding helmet 30, the detection system 12 may determine the position and/or the orientation of the welding torch 26 (e.g., as described above with respect to FIGS. 2-4) relative to the welding helmet 30. In addition, the detection system 12 may track the movement of the welding helmet 30 during a welding operation. Data from the detection system 12 may be displayed within the welding helmet 30. For example, data may be incorporated within a heads-up display of the helmet 30. The position of the helmet 30 may be associated with the position of the welding workpiece 28 and the welding torch 26. Images corresponding to the association may also be displayed. In certain embodiments a type of safety glasses may incorporate a camera and/or a display for capturing and/or displaying image data.

By detecting the position and the orientation of the welding torch 26 relative to the workpiece 28, a work angle (e.g., roll), a travel angle (e.g., pitch), a contact tip-to-work distance (CTWD), and/or a travel speed of the welding torch 26 may be determined. For example, FIG. 7 is an illustration of a work angle 94 of a welding operation. As illustrated, the work angle 94 is an angle 96 between the horizontal portion 70 of the workpiece 28 and a central axis 98 (e.g., this may be similar to the axis 54 described above) of the welding torch 26 as viewed from the side of the workpiece 28. As another example, FIG. 8 is an illustration of a travel angle 100 of a welding operation. The travel angle 100 is an angle 102 between the central axis 98 of the welding torch 26 and a vertical axis 104 of the vertical portion 68 of the workpiece



28. As illustrated, the vertical axis 104 extends parallel to the vertical portion 68 of the workpiece 28. Furthermore, the travel angle 100 is determined relative to a front view of the workpiece 28. As a further example, FIG. 9 is an illustration of a CTWD 108 of a welding operation. As illustrated, a welding electrode or welding wire 110 extends from the nozzle 46 of the welding torch 26. The CTWD 108 is a distance 112 between an upper surface of the horizontal portion 70 and a position 114 of the tip of the nozzle 46 of the welding torch 26.

As may be appreciated, welding data (e.g., the work angle, the travel angle, the CTWD, and/or the travel speed, among other data) may be provided by the welding training system 10 of FIG. 1 to a welding operator, instructor, and/or a supervisor during a welding operation (e.g., real or simulated). Furthermore, such welding data may be provided to the welding operator, instructor, and/or the supervisor after completion of the welding operation. In certain embodiments, the welding data may be provided on the display 22 of the detection system 12 in any suitable format (e.g., a welding score, charts, graphs, etc.) and/or to the audio device 24 of the detection system 12. Furthermore, a video playback of the welding operation (e.g., a three-dimensional rendering of the welding torch 26 as it moves along the workpiece 28, a virtual arc, a bead, and so forth) may be displayed on the display 22 of the detection system 12. In other embodiments, the welding operator may view welding data and/or three-dimensional rendering via a heads up display (e.g., in the welding helmet 30) or via virtual reality glasses. Accordingly, the welding operator may receive visual and/or audio clues to help them improve their welding technique. In certain embodiments, welding data may be provided (e.g., via a network) from multiple welding training systems 10 to a central location where the welding data from multiple welding training systems 10 may be compared (e.g., to compare performance of different welding operators).

In some embodiments, welding data output from the detection system 12 may provide the welding operator with a welding score. Furthermore, the welding data may be used as part of a welding game (e.g., a welding game software program executed by the processing device 20 of the detection system 12 and displayed on the display 22 of the detection system 12). For example, the welding data may be used to provide the welding operator with points that accumulate with each properly performed weld. In some embodiments, a simulated welding technique of the welding operator may be applied to a real world welding application. For example, the simulated welding technique might be applied to a chassis of a virtual racecar. After one or more simulated welds have been completed, the virtual racecar may be driven in a simulated race (e.g., on a racetrack) to see how the structure of the racecar handles environmental stresses (e.g., to test the structural integrity of the simulated welds). In certain embodiments, the virtual racecar may be controlled by the welding operator, or the virtual racecar may operate in an automated race that the welding operator may observe. Furthermore, the virtual racecar may compete against other virtual racecars (e.g., via a network) that have simulated welds performed by other welding operators to see how the virtual cars perform against each other.

In addition, in certain embodiments, the welding torch 26 may include built-in indicators to provide guidance to a welding operator. For example, FIG. 10 is a perspective view of the welding torch 26 having a welding guidance indicator 116 (e.g., display) to provide torch angle guidance (e.g., work angle guidance, travel angle guidance) and/or

travel speed guidance. Furthermore, FIG. 10A is a top view of the welding guidance indicator 116 of FIG. 10. As illustrated, the welding guidance indicator 116 may include multiple outputs 118 (e.g., arrows) that may act as guides for the welding operator. For example, one or more of the outputs 118 may illuminate to direct the welding operator to change the torch angle. In certain embodiments, when none (or all) of the outputs 118 are illuminated, the welding operator may be holding the welding torch 26 at a proper torch angle. As may be appreciated, the outputs 118 may flash at various speeds to indicate to the welding operator to increase and/or slow down travel speed.

Furthermore, in certain embodiments, the workpiece 28 may include a display to provide guidance to a welding operator. Accordingly, FIG. 11 is a perspective view of an embodiment of the workpiece 28 having a display 119. As illustrated, the display 119 may extend on surfaces of both the vertical portion 68 and the horizontal portion 70. As a welding operator performs a virtual welding operation, a virtual weld bead 120 may be shown on the display 119. Furthermore, a virtual welding arc 121 may be displayed on the display 119. As illustrated, the display 119 may also include outputs 122 (e.g., arrows) that may direct the welding operator. For example, one or more of the outputs 122 may illuminate (e.g., output 124) to direct the welding operator to change their torch angle. In certain embodiments, when none (or all) of the outputs 122 are illuminated on the display 119, the welding operator may be holding the welding torch 26 at a proper torch angle. As may be appreciated, in some embodiments, the outputs 122 may flash at various speeds on the display 119 to indicate to the welding operator to increase and/or slow down travel speed. Furthermore, a target position 126 (e.g., crosshairs target) may be displayed on the display 119 to illustrate where the virtual weld bead 120 should be if the travel speed of the welding torch 26 were correct.

In certain embodiments, the workpiece 28 may be a virtual workpiece and may therefore be incorporated into the display 22 of the detection system 12. Accordingly, FIG. 12 is a perspective view of an embodiment of a virtual workpiece 128 shown on the display 22 of the detection system 12. In certain embodiments, the virtual workpiece 128 may include markers 32, 34, 36, and 38 (e.g., virtual markers) configured to be detected by the motion detecting device 14. As illustrated, a welding operator 130 may hold the welding torch 26 up to the display 22 to perform a virtual weld on the virtual workpiece 128. As may be appreciated, the display 22 may be any suitable display. For example, the display 22 may be a liquid crystal display (LCD) screen, a tablet computer, computer monitor, television, touchscreen, and so forth. Furthermore, the virtual workpiece 128 may be configured with markers (e.g., such as the markers described in detail above) to be detected by the detection system 12. In such an embodiment, the detection system 12 may be synchronized with the display 22 to minimize flicker. In some embodiments, a holographic projection may be used to display the virtual workpiece 128, a virtual welding bead, and/or a virtual welding arc, among other things. In addition, the virtual workpiece 128 may include virtual guides to direct a welding operator to change their torch angle and/or travel speed. Certain embodiments may also display a virtual representation of the welding torch 26. In such embodiments, the virtual weld may be performed a suitable distance away from the display 22, such as by using a welding workpiece 28.

FIG. 13 is an embodiment of a method 132 for determining a position and an orientation of the welding torch 26 and

the workpiece 28. A first marker of the welding torch 26 may be detected using the motion detecting device 14 of the detection system 12 (block 134). Furthermore, a second marker of the welding torch 26 may be detected using the motion detecting device 14 (block 136). Likewise, a first marker of the workpiece 28 may be detected using the motion detecting device 14 (block 138) and a second marker of the workpiece 28 may be detected using the motion detecting device 14 (block 140). As may be appreciated, detecting a first or second marker using the motion detecting device 14 may include detecting a size, shape, and/or color of the marker. The position and the orientation (e.g., pitch, roll, etc.) of the welding torch 26 and the workpiece 28 may be calculated using the first and second markers of the welding torch 26 and the first and second markers of the workpiece 28 (e.g., via the detection system 12) (block 142). For example, a relative position and a relative orientation of the welding torch 26 may be calculated in relation to the workpiece 28. Furthermore, a virtual representation of the welding torch 26 and/or the workpiece 28 may be shown on the display 22 of the detection system 12 (block 144). In addition, a virtual position and/or a virtual orientation of the welding torch 26 on the display 22 may be adjusted as the position and the orientation of the welding torch 44 changes (block 146). As may be appreciated, the display 22 may also include virtual guides (e.g., a target value, a range of values, etc.) to direct the welding operator to a proper torch angle (e.g., pitch, roll, etc.) and/or a proper travel speed.

As may be appreciated, using the systems, devices, and techniques described herein, a low cost welding training system 10 may be provided for training welding operators. The welding training system 10 may allow a greater number of welding operators to be trained and may provide the welding operators with a greater amount of time to use the welding training system 10 (e.g., due to its low cost). Furthermore, as described above, a gaming aspect of welding training may be provided to welding operators to enhance welding operator interest in the welding training system 10.

While only certain features of the invention have been illustrated and described herein, many modifications and changes will occur to those skilled in the art. It is, therefore, to be understood that the appended claims are intended to cover all such modifications and changes as fall within the true spirit of the invention.

The invention claimed is:

1. A welding training system comprising:
  - a position detecting system configured to detect a device distance between the position detecting system and a device within a field of view of the position detecting system, to detect a plurality of distances between the position detecting system and all other objects within the field of view of the position detecting system, and to produce a map corresponding to the device and to the other objects based at least in part on the detected device distance and the detected plurality of distances; and
  - a plurality of markers configured to be coupled to the device of the welding training system, wherein the plurality of markers is configured to be detected by the position detecting system to detect the device distance.
2. The welding training system of claim 1, comprising a processing device configured to determine a position of the device based at least partly on data received from the position detecting system.

3. The welding training system of claim 1, comprising a processing device configured to determine an orientation of the device based at least partly on data received from the position detecting system.

4. The welding training system of claim 1, comprising a processing device configured to determine a pitch of the device, a roll of the device, a yaw of the device, or some combination thereof, based at least partly on data received from the position detecting system.

5. The welding training system of claim 1, comprising a processing device configured to determine a travel speed of the device based at least partly on data received from the position detecting system.

6. The welding training system of claim 1, wherein the device comprises a welding torch having the plurality of markers coupled thereon.

7. The welding training system of claim 1, wherein the position detecting system is configured to create a three-dimensional (3D) point cloud, to detect the device distance between the position detecting system and the device within the field of view of the position detecting system based at least in part on the 3D point cloud, and to detect the plurality of distances between the position detecting system and all other objects within the field of view of the position detecting system based at least in part on the 3D point cloud.

8. The welding training system of claim 1, wherein the position detecting system comprises a commercially available off-the-shelf computer accessory.

9. The welding training system of claim 1, comprising a welding workpiece having the plurality of markers coupled thereon.

10. The welding training system of claim 1, wherein each marker of the plurality of markers is different in shape, size, or color, or any combination thereof.

11. A welding training system comprising:
 

- a position detecting system configured to detect a device distance between the position detecting system and a welding torch within a field of view of the position detecting system, to detect a plurality of distances between the position detecting system and other objects within the field of view of the position detecting system, and to produce a map corresponding to the welding torch and to the other objects, wherein the other objects comprise a display;
- a first plurality of markers configured to be coupled to the welding torch, wherein the first plurality of markers is configured to be detected by the position detecting system to detect the device distance; and
- the display configured to present a virtual workpiece and a simulated weld on the virtual workpiece when the welding torch is moved along the virtual workpiece.

12. The welding training system of claim 11, comprising a processing device configured to determine a position and an orientation of the welding torch based at least partly on data received from the position detecting system.

13. The welding training system of claim 11, comprising a processing device configured to determine a pitch of the welding torch relative to the virtual workpiece, a roll of the welding torch relative to the virtual workpiece, a yaw of the welding torch relative to the virtual workpiece, or some combination thereof, based at least partly on data received from the position detecting system.

14. The welding training system of claim 11, comprising the welding torch having the first plurality of markers coupled thereon.

15. The welding training system of claim 11, wherein the virtual workpiece comprises a second plurality of markers,

and the second plurality of markers is configured to be detected by the position detecting system.

16. The welding training system of claim 11, wherein the position detecting system comprises one or more emitters, an infrared camera, and an RGB camera. 5

17. The welding training system of claim 11, wherein the display comprises a touchscreen.

18. The welding training system of claim 11, wherein the virtual workpiece comprises a liquid crystal display screen, a computer monitor, or a television. 10

19. The welding training system of claim 11, wherein the display is synchronized with the position detecting system to minimize flicker.

20. The welding training system of claim 11, wherein the display is configured to present virtual guides to adjust a 15  
torch angle of the welding torch relative to the simulated weld, a travel speed of the welding torch relative to the simulated weld, or any combination thereof.

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